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Results 1 - 10 of about 204,000 for **dual arms robot and interpolation** (0.10 seconds)

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Students can make their own **interpolation** algorithm and com- ... back control of a **dual-arm robot**. IEEE int symp on industr electron, ...

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**Dual-arm Robot** Simulation System (DRSS). It can simulate. **dual-arm** kinematics and dynamics .... points using cubic polynomical **interpolation** in joint space. ...

[ieeexplore.ieee.org/iel2/629/5875/00225061.pdf?arnumber=225061](http://ieeexplore.ieee.org/iel2/629/5875/00225061.pdf?arnumber=225061) - [Similar pages](#)

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introduction of the **dual-arm robot**. In the newly equipped. differential assembly line which has ... **interpolation** point over the target trajectory without ...

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UR APPROACH. We implemented a similar approach as in [10] for **dual-arm**. movements that also uses HMM to imitate movements shown. to a **robot** multiple times. ...

[www.iaim.ira.uka.de/data/File/Publications/Humanoids2006\\_imitation.pdf](http://www.iaim.ira.uka.de/data/File/Publications/Humanoids2006_imitation.pdf) - [Similar pages](#)

**Dual-arm generalized compliant motion with shared control - Patent ...**

The invention relates to **dual arm robot** control systems and in particular ..... The Cartesian **interpolation** is described by the input parameters timeSpeed, ...

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DOF **dual-arm robot** (shown in Figure 3). This. **robot** contains built in motion planning at the ... improvement over linear **interpolation** for all of ...

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will present its seven-axis IA20 and 13-axis **dual-arm robot** DA20 at this ... Coordinated movements of the **arms**, in various types of **interpolation** ...

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the **robot**. Linear **interpolation** is used to reach to points. in the shaded area. See also Figure 5. .... **dual-ported ram** (dpram) memory interface. One of the ...

[www.ai.mit.edu/projects/cog/Publications/mattw-sab96.ps.gz](http://www.ai.mit.edu/projects/cog/Publications/mattw-sab96.ps.gz) - [Similar pages](#)

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4528632 Industrial articulated **robot** linear **interpolation** control device Jul ... 6121743 **Dual**  
robotic **arm** end effectors having independent yaw motion Sep 19 ...  
text.usg.edu:8080/tt/www.google.com/patents?vid=USPAT3920972 - 30k -  
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Apparatus and method of distributing object handling - US Patent ...

Dual-arm manipulators with adaptive control Issued on: June 11, 1991 ... Behera et al.,  
Neuro-adaptive Hybird Controller for **Robot-Manipulator** Tracking ...  
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Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
S1	2347	700/245-252.ccls.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/14 12:25
S2	1426	S1 and (robot near1 control\$4)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/16 16:36
S3	1259	S2 and (two near1 flange\$1)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/14 12:26
S4	2347	700/245-252.ccls.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/14 14:03
S5	1426	S4 and (robot near1 control\$4)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/14 14:03
S6	1259	S5 and (two near1 flange\$1)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/14 14:03
S7	216	S6 and interpolat\$3	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/14 14:03
S8	33	S7 and @rlad<"20020604"	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/14 14:07
S9	0	("2003/0171847").URPN.	USPAT	OR	ON	2007/08/15 10:33
S10	2347	700/245-252.ccls.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/15 10:33
S11	1	S10 and (two adj1 flanges)	USPAT	OR	ON	2007/08/15 10:34

## EAST Search History

S12	12	S10 and (two adj1 tool\$1)	USPAT	OR	ON	2007/08/15 10:34
S13	45	("3890552").URPN.	USPAT	OR	ON	2007/08/15 10:48
S14	1	("5315222").PN.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	OFF	2007/08/16 16:37
S15	16	("5315222").URPN.	USPAT	OR	ON	2007/08/16 16:57
S16	0	ep1468791.pn.	US-PGPUB; USPAT; EPO; DERWENT; IBM_TDB	OR	ON	2007/08/16 16:58
S17	0	ep1468791	US-PGPUB; USPAT; EPO; DERWENT; IBM_TDB	OR	ON	2007/08/16 17:00
S18	2	"5825980"	US-PGPUB; USPAT; EPO; DERWENT; IBM_TDB	OR	ON	2007/08/16 17:06
S19	1	("5157315").PN.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	OFF	2007/08/16 17:06
S20	18	("5157315").URPN.	USPAT	OR	ON	2007/08/16 17:46
S21	1	("6121743").PN.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	OFF	2007/08/16 17:47
S22	1	S21 and (two near1 effector\$1)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 10:00
S23	0	S22 and interpolat\$3	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/16 17:47
S24	79390	"318"/\$.ccls.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 10:00

## EAST Search History

S25	1315	S24 and (robot near1 control\$4)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/16 17:48
S26	18	S25 and (two adj1 (hands or effectors or flanges))	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/16 18:06
S27	0	S26 and interpolat\$3	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/16 17:48
S28	1	S26 and singularity	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/16 18:06
S29	0	(plurality near1 tools) same (single adj1 robot)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 10:02
S30	1	(two near1 grippers) same (single adj1 robot)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 10:04
S31	11	(two near1 end adj1 effectors) same (single adj1 robot)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 10:10
S32	3	(two near1 end adj1 effectors) same (robot) and interpolation	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 10:18
S33	1	("4821207").PN.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	OFF	2007/08/17 10:20
S34	1	("6025852").PN.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	OFF	2007/08/17 10:44

## EAST Search History

S35	1	("20040001750").PN.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	OFF	2007/08/17 10:45
S36	0	S35 and interpolat\$3	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 11:41
S37	1	("6450755").PN.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	OFF	2007/08/17 11:59
S38	98983	"414"/\$.ccls.	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 11:59
S39	42	S38 and (dual adj1 arms same robot)	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 12:00
S40	0	S39 and interpolat\$3	US-PGPUB; USPAT; USOCR; FPRS; IBM_TDB	OR	ON	2007/08/17 12:00